AMENDMENTS TO THE CLAIMS

A complete listing of all claims in the application is provided below with the requested amendments marked.

1. (currently amended) A device for use in a milking parlour for automatically milking an animal using a milking robot, the device comprising a robot arm construction for automatically connecting a teat cup to a teat of the animal to be milked, the robot arm construction comprising:

a first robot arm construction portion;

a second robot arm construction portion;

a first generally horizontal axis at which the first robot arm construction portion pivots;

a second generally horizontal axis at which the second robot arm construction portion is pivotably connected to the first robot arm construction portion;

a third robot arm construction portion for carrying a teat cup, the third robot arm construction portion being connected to the second robot arm construction portion for pivotable movement under the udder of the animal; and

a first actuator for moving the first robot arm construction portion, having a first point of application on the first robot arm construction portion and having a second point of application located below the first generally horizontal axis and below the first point of application.

2. (original) The device as claimed in claim 1, wherein a fencing surrounds the milking parlour and the first robot arm construction portion is pivotably connected to an upper side of the fencing at the first horizontal axis and the second horizontal axis is located outside the milking parlour.

3. (original) The device as claimed in claim 2, wherein the second point of application of the first actuator is located on the fencing at a place located at a first distance below the first horizontal axis.

4. (original) The device as claimed in claim 2, wherein the robot arm construction comprises a second actuator having a first point of application on the second robot arm

construction portion and having a second point of application on the fencing at a place located a second distance below the first generally horizontal axis.

5. (original) The device as claimed in claim 3, wherein the robot arm construction comprises a second actuator having a first point of application on the second robot arm construction portion and having a second point of application on the fencing at a place located a second distance below the first generally horizontal axis, the second distance being less than the first distance.

6. (original) The device as claimed in claim 5, wherein the first point of application on the second robot arm construction portion is located at least approximately half-way along the second robot arm construction portion.

7. (original) The device as claimed in claim 5, wherein the first point of application on the second robot arm construction portion is located on a side of the second robot arm construction portion located facing the fencing.

8. (original) The device as claimed in claim 1, wherein the first point of application on the first robot arm construction portion is located closer to the second horizontal axis than to the first horizontal axis.

9. (previously presented) The device as claimed in claim 1, wherein the first point of application on the first robot arm construction portion faces the third robot arm construction portion.

10. (original) The device as claimed in claim 1, wherein a fencing surrounds the milking parlour and the device comprises a supporting unit movable along the fencing, the first robot arm construction portion being pivotably connected to the supporting unit at the first horizontal axis.

11. (original) The device as claimed in claim 10, wherein the first actuator has a second point of application on the supporting unit and wherein the robot arm construction comprises a second actuator having a first point of application on the second robot arm construction portion and having a second point of application on the supporting unit.

12. (original) The device as claimed in claim 11, wherein the supporting unit is movable along two rails that are disposed at different levels on the fencing.

13. (original) The device as claimed in claim 12, wherein the supporting unit is movable along the rails by means of a third actuator.

14. (original) The device as claimed in claim 1, further comprising a position-determining device for determining the position of a teat of a cow, the first actuator being controllable with the aid of data from the position-determining device.

15. (original) The device as claimed in claim 4, further comprising a position-determining device for determining the position of a teat of a cow, the second actuator being controllable with the aid of data from the position-determining device.

16. (previously presented) The device as claimed in claim 1, wherein the third robot arm construction portion is pivotally connected to the second robot arm construction portion.

17. (previously presented) The device as claimed in claim 2, wherein the third robot arm construction portion is pivotally connected to the second robot arm construction portion.

18. (previously presented) A device for automatically milking an animal, the device comprising:

a milking parlour comprising a fencing; and

a milking robot, including a robot arm construction for automatically connecting a teat cup to a teat of the animal to be milked, wherein the robot arm construction comprises:

a first robot arm construction portion;

a second robot arm construction portion;

a first generally horizontal axis at which the first robot arm construction portion pivots with respect to the fencing;

a second generally horizontal axis at which the second robot arm construction portion is pivotably connected to the first robot arm construction portion;

a third robot arm construction portion for carrying a teat cup, the third robot arm construction portion being connected to the second robot arm construction portion for pivotable movement under the udder of the animal; and

a first actuator having a first point of application on the first robot arm construction portion and having a second point of application on the fencing located a first distance generally below the first generally horizontal axis and below the first point of application.

19. (previously presented) The device as claimed in claim 1, wherein the third robot arm construction portion is rigidly connected to the second robot arm construction portion.

20. (previously presented) The device as claimed in claim 18, wherein the third robot arm construction portion is rigidly connected to the second robot arm construction portion.

21. (previously presented) The device as claimed in claim 1, wherein the robot arm construction further comprises a second actuator having a point of application on the second robot arm construction portion and the first and second actuators cross one another.

22. (previously presented) The device as claimed in claim 18, wherein the robot arm construction further comprises a second actuator having a first point of application on the second robot arm construction portion and a second point of application on the fencing at a place located a second distance below the first generally horizontal axis, the second distance being less than the first distance, and whereby the first and second actuators cross one another.